$$I_{\text{berror}} = \frac{32.96 - 33.01}{32.96} \cdot 100\ \%$$

$I_{\text{berror}} = -0.15\%$

(8) Calculate the inertia error for each mean value of base inertia from paragraph (c)(6) of this section. Use Equation 1066.265–2, substituting the mean base inertias associated with each acceleration and deceleration rate for the individual base inertias.

(d) *Performance evaluation.* The dynamometer must meet the following specifications to be used for testing under this part:

(1) The base inertia error determined under paragraph (c)(7) of this section may not exceed ±0.50% relative to any individual value.

(2) The base inertia error determined under paragraph (c)(8) of this section may not exceed ±0.20% relative to any mean value.

§ 1066.255 Parasitic loss verification.

(a) *Overview.* Verify and correct the dynamometer's parasitic loss. This procedure determines the dynamometer's internal losses that it must overcome to simulate road load. These losses are characterized in a parasitic loss curve that the dynamometer uses to apply compensating forces to maintain the desired road-load force at the roll surface.

(b) *Scope and frequency.* Perform this verification upon initial installation, within 7 days of testing, and after major maintenance.

(c) *Procedure.* Perform this verification by following the dynamometer manufacturer's specifications to establish a parasitic loss curve, taking data at fixed speed intervals to cover the range of vehicle speeds that will occur during testing. You may zero the load cell at the selected speed if that improves your ability to determine the parasitic loss. Parasitic loss forces may never be negative. Note that the torque transducers must be zeroed and spanned prior to performing this procedure.

(d) *Performance evaluation.* In some cases, the dynamometer automatically updates the parasitic loss curve for further testing. If this is not the case, compare the new parasitic loss curve to the original parasitic loss curve from the dynamometer manufacturer or the most recent parasitic loss curve you programmed into the dynamometer. You may reprogram the dynamometer to accept the new curve in all cases, and you must reprogram the dynamometer if any point on the new curve departs from the earlier curve by more than ±4.5 N (±1.0 lbf).

§ 1066.260 Parasitic friction compensation evaluation.

(a) *Overview.* This section describes how to verify the accuracy of the dynamometer's friction compensation.

(b) *Scope and frequency.* Perform this verification upon initial installation, within 7 days before testing, and after major maintenance. Note that this procedure relies on proper verification or calibration of speed and torque, as described in §§ 1066.235 and1066.240. You must also first verify the dynamometer's parasitic loss curve as specified in § 1066.255.

(c) *Procedure.* Use the following procedure to verify the accuracy of the dynamometer's friction compensation:

(1) Warm up the dynamometer as specified by the dynamometer manufacturer.

(2) Perform a torque verification as specified by the dynamometer manufacturer. For torque verifications relying on shunt procedures, if the results do not conform to specifications, recalibrate the dynamometer using NIST-traceable standards as appropriate until the dynamometer passes the torque verification. Do not change the dynamometer's base inertia to pass the torque verification.

(3) Set the dynamometer inertia to the base inertia with the road-load coefficients A, B, and C set to 0. Set the dynamometer to speed-control mode with a target speed of 10 mph or a higher speed recommended by the dynamometer manufacturer. Once the speed stabilizes at the target speed, switch the dynamometer from speed control

to torque control and allow the roll to coast for 60 seconds. Record the initial and final speeds and the corresponding start and stop times. If friction compensation is executed perfectly, there will be no change in speed during the measurement interval.

(4) Calculate the friction compensation error, $FC_{error,}$ using the following equation:

$$FC_{error} = \frac{I}{2 \cdot t} \cdot \left(S_{final}^2 - S_{init}^2\right)$$

Eq. 1066.260-1

Where:

I = dynamometer inertia setting, in lbf·s²/ft.

t = duration of the measurement interval, accurate to at least 0.01 s.

S_{final} = the roll speed corresponding to the end of the measurement interval, accurate to at least 0.1 mph.

S_{init} = the roll speed corresponding to the start of the measurement interval, accurate to at least 0.1 mph.

Example:

I = 2000 lbm = 62.16 lbf· s²/ft

t = 60.0 s

S_{final} = 9.2 mph = 13.5 ft/s

S_{init} = 10.0 mph = 14.7 ft/s

$$FC_{error} = \frac{62.16}{2 \cdot 60.00} \cdot \left(13.5^2 - 14.7^2\right)$$

FC_{error} = −16.5 ft·lbf/s = −0.031 hp

(5) The friction compensation error may not exceed ±0.1 hp.

§ 1066.265 Acceleration and deceleration verification.

(a) *Overview.* This section describes how to verify the dynamometer's ability to achieve targeted acceleration and deceleration rates. Paragraph (c) of this section describes how this verification applies when the dynamometer is programmed directly for a specific acceleration or deceleration rate. Paragraph (d) of this section describes how this verification applies when the dynamometer is programmed with a calculated force to achieve a targeted acceleration or deceleration rate.

(b) *Scope and frequency.* Perform this verification upon initial installation and after major maintenance.

(c) *Verification of acceleration and deceleration rates.* Activate the dynamometer's function generator for measuring roll revolution frequency. If the dynamometer has no such function generator, set up a properly calibrated external function generator consistent with the verification described in this paragraph (c). Use the function generator to determine actual acceleration and deceleration rates as the dynamometer traverses speeds between 10 and 40 mph at various nominal acceleration and deceleration rates. Verify the dynamometer's acceleration and deceleration rates as follows:

(1) Set up start and stop frequencies specific to your dynamometer by identifying the roll-revolution frequency, *f*, in revolutions per second (or Hz) corresponding to 10 mph and 40 mph vehicle speeds, accurate to at least four significant figures, using the following equation: